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Amendments to the Claims:

This list of claims will replace all prior versions, and listings, of claims in the application:

Listing of Claims:

1. (currently amended) A method for determining a feature location, comprising:

providing left and right camera images of the feature;

locating the feature in the left camera image and in the right camera image using bunch graph matching; and

determining the feature location in multiple dimensions including depth based on the feature locations in the left camera image and the right camera image.

2. (currently amended) A method for determining a feature location, comprising:

providing left and right camera images of the feature;

locating the feature in the left camera image and in the right camera image using image analysis based on wavelet component values generated from wavelet transformations of the camera images; and

determining the feature location in multiple dimensions including depth based on the feature locations in the left camera image and the right camera image.

3. (original) A method for determining a feature location as defined in claim 2, wherein the wavelet transformations use Gabor wavelets.

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4. (currently amended) Apparatus for determining a feature location, comprising:

means for providing left and right camera images of the feature;

means for locating the feature in the left camera image and in the right camera image using image analysis based on wavelet component values generated from wavelet transformations of the camera images; and

means for determining the feature location in multiple dimensions including depth based on the feature locations in the left camera image and the right camera image.

5. (currently amended) Apparatus A method for determining a feature location as defined in claim 4, wherein the wavelet transformations use Gabor wavelets.

6. (original) A method for determining a feature location, comprising:

providing first and second spaced-apart camera images of the feature;

locating the feature in the first camera image using image analysis based on wavelet component values generated from wavelet transformations of the first camera image and locating the feature in the second camera image; and

determining the feature location in multiple dimensions including depth based on the feature location in the first camera image and the feature location in the second camera image.

7. (original) A method for determining a feature location as defined in claim 6, wherein the wavelet transformations use Gabor wavelets.

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8. (new) Apparatus for determining a feature location, comprising:

means for providing left and right camera images of the feature;

means for locating the feature in the left camera image and in the right camera image using bunch graph matching; and

means for determining the feature location in multiple dimensions including depth based on the feature locations in the left camera image and the right camera image.

9. (new) Apparatus for determining a feature location, comprising:

means for providing first and second spaced-apart camera images of the feature;

means for locating the feature in the first camera image using image analysis based on wavelet component values generated from wavelet transformations of the first camera image and locating the feature in the second camera image; and

means for determining the feature location in multiple dimensions including depth based on the feature location in the first camera image and the feature location in the second camera image.

10. (new) Apparatus for determining a feature location as defined in claim 9, wherein the wavelet transformations use Gabor wavelets.